

# Data-Driven Structural Health Monitoring using Feature Fusion and Hybrid Deep Learning

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**Abstract**—Smart structural health monitoring (SHM) for large-scale infrastructures is an intriguing subject for engineering communities thanks to its significant advantages such as timely damage detection, optimal maintenance strategy, and reduced resource requirement. Yet, it is a challenging topic as it requires handling a large amount of collected sensors data continuously, which is inevitably contaminated by random noises. Therefore, this study developed a practical end-to-end framework that makes use of physical features embedded in raw data and an elaborated hybrid deep learning model, namely 1DCNN-LSTM, featuring two algorithms - Convolutional Neural Network (CNN) and Long-Short Term Memory (LSTM). In order to extract relevant features from sensory data, the method combines various signal processing techniques such as the autoregressive model, discrete wavelet transform, and empirical mode decomposition. The hybrid deep learning 1DCNN-LSTM is designed based on the CNN's capacity of capturing local information and the LSTM network's prominent ability to learn long-term dependencies. Through three case studies involving both experimental and synthetic datasets, it is demonstrated that the proposed approach achieves highly accurate damage detection, as accurate as the powerful two-dimensional CNN, but with a lower time and memory complexity, making it suitable for real-time SHM.

**Note to Practitioners:** This manuscript aims to develop a practical data-driven method for automatically monitoring the operational state of structures. In order to achieve consistently and highly accurate results in performing different tasks for diverse structures, we combine underlying features in both time and frequency domains extracted from measured signal vibration data. Three popular data featuring methods are combined to achieve the diversity gain which would not be possible with each individual method. As the vibration is usually measured by long time-series signals, the most efficient deep learning architecture for time-series signal, namely Long-Short Term Memory (LSTM), is considered for this work. Besides, each structure has its own dynamic properties, i.e., eigen frequencies, around which the most relevant information is in the frequency domain, thus Convolutional Neural Network specifically designed for capturing local information is used in combination with LSTM, forming a hybrid Deep Learning architecture. The applicability and effectiveness of the proposed approach are supported by three case studies with

different types of structures, showing highly accurate damage detection with reduced resource requirements. These advantages can be valuable for developing a model for live monitoring of structural health in the future life-line infrastructures.

**Index Terms**—Structural health monitoring, deep learning, signal processing, damage detection, vibration, dynamic analysis.

## I. INTRODUCTION

**L**ARGE-SCALE civil structures are expensive assets playing a vital role in society [1] as they ensure smooth transportation and improve the quality of people's daily life. However, they are permanently exposed to various unpredicted excitations involving wind loads, vehicular loads, accidental loads, environmental changes, and even earthquakes. Towards intelligent and real-time monitoring, the data-driven model recently emerges as a promising alternative to other techniques, which provides unprecedented advantages such as timely detecting damage, predicting structural behaviors in extreme scenarios, and optimizing maintenance strategies. However, it is challenging to design a high-performance algorithm dealing with a large volume of data for long-term structural health monitoring.

The Autoregressive (AR) model belonging to the time-domain class is widely used when working with sensor data in many sectors such as civil, mechanical engineering, information technology, healthcare, etc. Sohn et al. [2] used AR in combination with the X-bar control chart to handle vibration-based damage detection problems of concrete bridge columns. It is shown that the method is able to identify all investigated damage levels in an unsupervised learning fashion, which is significantly useful in real application because of the scarcity of data related to different damage scenarios. Entezami et al. [3] developed a fast unsupervised approach for SHM having the capability of dealing with large vibration data based on the AR models for feature extraction and Kullback-Leibler distance for classification. The applicability of the method was supported through both numerical simulation and experimental datasets, with emphasis on its computational efficiency and highly accurate damage localization. Carden and Brownjohn [4] developed a derived AR technique called autoregressive moving average model (ARMA), to assess respective conditions of a structure in service, a.k.a the level 1 of SHM. The method was proved to distinguish the health state from various damaged ones through three datasets acquired from the laboratory IASC-ASCE benchmark structure and two real-world structures, i.e., the Z24 bridge and the

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Singapore–Malaysia Second Link Bridge. However, the AR-based methods require mathematically elaborated criteria and manual thresholds to classify time-series into corresponding classes. These thresholds are usually sensitive not only to structures' properties but also to characteristics of excitation and environmental parameters.

In reality, the correctness of a time-domain technique may be impaired by unwanted noise, then techniques in time-frequency domain are developed, of which the Wavelet Transform (WT) is commonly appreciated by its ability to provide a proper representation of data with multiple time and frequency resolutions. Pnevmatikos et al. [5] achieved high accurate results in damage localization of a steel frame structure by estimating the difference of wavelet coefficients extracted from acceleration measurements of undamaged and damaged structures subjected to an earthquake. For long term structural health monitoring of bridges, Zeng et al. [6] employed WT to discern characteristics in both time and frequency domain of structures responses under external excitation such as temperature variation and traffic loads. Recently, Ma et al. [7] combined WT and independent component analysis to identify sudden stiffness loss of a nonlinear hysteretic structure in a fast and accurate fashion.

On the other hand, an adaptive technique called Empirical Mode Decomposition (EMD), which is able to retain local characteristics of data, has received increasing interest. For bridge damage detection under vehicular load, Obrien et al. [8] found that Intrinsic Mode Functions corresponding to pseudo-frequency, obtained from EMD are sensitive to damage and can serve as effective indicators for damage localization. Sadhu [9] investigated a hybrid EMD method to address the potential mode mixing issue of the traditional EMD method. The proposed method was then applied to perform modal identification and achieved accurate results, for example, modal assurance criteria of higher than 0.98, despite measurement noise and closely-spaced modes. In [10], Xiao et al., developed an extension of the EMD to analyze the acceleration response of the Chulitna River bridge in Alaska to a moving vehicle, which could provide clear transient frequencies with high resolution without the need of linearity assumptions required by Fourier transform-based methods.

Another way to work with measured time series data is to convert them into two-dimensional graphical representations, then using computer vision algorithms to detect the corresponding states of the physical object. Tang et al. [11] applied a two dimensional convolution neural network (2DCNN) to the anomaly detection problem of a long-span cable-stayed bridge, utilizing 2D representation of accelerometer sensor signals. Their results suggested that the 2DCNN approach performed better than the existing method in structural anomaly detection, and was scalable to include more signal data from multiple measurements. This idea is also supported by research in other domains, for example, the works of [12], [13] in machine fault diagnosis.

Although 2DCNN is a powerful algorithm for structural damage detection tasks, the network requires 2D time-frequency representation of the 1D sensor time-series, and subsequent image management process including proper selection

of parameters for image conversion, labeling images, splitting images into separate training/validation/ testing folder, moreover when performing a new task with same data or new label incorporated, the whole process related to image needs to repeat, or even to duplicate existing images. Besides, reviewed signal processing techniques have their own advantages but also drawbacks such as manual thresholds, high time complexity, and less flexibility to adapt to different structures. And, it is likely using features in only one domain (time or frequency) might provide good results for some specific problems but not for others. In addition, toward an intelligent SHM, its components should be robust to different scenarios, and flexible to various tasks in order to facilitate the incorporation of new events and lower required resources in terms of time, complexity, memory, budget, etc., as much as possible. Therefore, this study develops a practical data-driven method for monitoring the operational state of structures using Feature Fusion and Hybrid Deep Learning. The proposed method operates on processed data where relevant features extracted from sensory data using signal processing techniques involving Autoregressive model, Discrete Wavelet Transform, and Empirical Mode Decomposition, are integrated into three-dimensional tensors of features which enter further into a hybrid deep learning model, called 1DCNN-LSTM, to identify corresponding structural conditions. The 1DCNN-LSTM is designed based on the ability to capture local connectivity of the Convolutional Neural Network (CNN) and the well-known performance in accounting for long-term dependencies of Long-Short Term Memory (LSTM) network. By doing so, the unobserved underlying patterns at multi-level, multi-scale, and multi-domain embedded in raw structure responses can be extracted and favor damage detection performance. The main contributions of the work are summarized as follows:

- An end-to-end hybrid DL framework is developed for structural damage detection, that includes raw data processing, data augmentation, data fusion, a hybrid 1DCNN-LSTM model, and damage detection outcomes.
- The correctness and effectiveness of the proposed framework are demonstrated through three case studies, including two experimental and one synthetic database. It achieves comparable performance with 2DCNN method while having time complexity reduced by more than 50% and no supplement storage required for images.
- From the proposed method, various studies are conducted to provide insights into the effect of different parameters on structural damage detection performance: i) the method maintains a good performance when there is data contamination of up to 10% random noise; ii) a reduction in length (10%) of input time-series can lead to a significant decrease in detection accuracy (20%); and iii) increasing the number of sensors effectively improves the damage detection accuracy.

The remainder of this paper is organized as follows. Section 2 briefly introduces various signal processing techniques. Section 3 details the architecture of the hybrid Deep Learning algorithm. Section 4 presents the validation of the method via three case studies. Finally, Section 5 draws conclusions and

gives some ideas for future work.

## II. FEATURE EXTRACTION FOR SENSOR TIME-SERIES DATA

Acceleration time series obtained from sensor  $j$  is denoted by  $x_j(t)$ , and a system with  $S$  accelerometers will provide multivariate time series  $X = \langle x_1(t), x_2(t), \dots, x_S(t) \rangle$ . It is well known that the distance from sensors to damage location is sensitive to the performance of any structural damage detection (SDD) method, hence, a SDD method aggregating multiple sensors data will enable to detect potential damages across the whole structure. However, working with multiple time-series data is challenging due to multiple factors such as the curse of dimensionality, long lengths of time series, skewed distribution of measured values, and noise due to device instability, transmission error, signal distortion and so on. Therefore, it is beneficial to extract underlying features from raw measured data beforehand, then using these extracted features to perform SDD tasks. In the literature, there are a large number of signal preprocessing techniques classified into three groups: time domain, frequency domain, and time-frequency domain, which can capture different unobserved features embedded in time series data. The following subsection describes in detail the techniques adopted in this work.

### A. Autoregressive Model

Autoregressive (AR) modelling is a time-domain method used to predict future values of time series data based on previous ones. This technique is adopted here owing to its practicality, effectiveness, and popularity. The number of previous values used in calculation corresponds to the order of the AR model whose formula is expressed as follows [14]:

$$x_{t,j} = \sum_{k=1}^p \phi_{k,j} x_{t-k,j} + e_{t,j}, \quad (1)$$

in which the subscript  $t$  denotes the time stamp,  $j$  stands for the sensor number,  $p$  is the order of AR model,  $\Phi = [\phi_1, \dots, \phi_p]$  stands for AR parameters,  $e_{t,j}$  is the residual error, i.e., the deviation between the estimated value and the measured one at timestamp  $j$ . If  $p = 1$ , the current value is only affected by the immediately previous value, if  $p = 2$ , two previous values are needed, and so on. One of the most common ways to determine the AR parameter is the ordinary least squares. Given  $N$  signal readings  $\langle x_{1,j}, x_{2,j}, \dots, x_{N,j} \rangle$ , the AR parameters are estimated to minimize the following square:

$$\Phi_j^{es} = \min_{\Phi} \sum_{t=p+1}^N [x_{t,j} - \phi_{1,j}x_{t-1,j} - \dots - \phi_{p,j}x_{t-p,j}]^2. \quad (2)$$

In this work, the AR model is determined based on the signal data measured from the intact structural state. Afterward, the obtained AR models are applied to other structural states and the residual errors between the measured values and predicted ones are derived. It is assumed that the nonlinearity caused by damage will lead to significant residual errors, while slight modification of structural parameters only introduces linear

variation to the baseline condition, thus, associated residual errors are at a low level. That is why performing SDD on residual errors from the AR model can boost the detection accuracy.

### B. Short Time Fourier Transformation

On the other hand, the time-series signal can also be represented in the frequency domain via Fourier transformation (FT). For civil structures, the frequency range of interest depends on both dynamic characteristics of structures and external excitation, which can exhibit time-dependent (nonlinear) behavior. Thereby, the Short-Time Fourier Transform (STFT) technique is developed by scientists, which renders a 1D time-series in a 2D image of time-frequency-amplitude representation. Specifically, a long signal is divided into shorter segments of equal length, then FT is applied to each segment. Mathematically, the STFT is formulated as follows:

$$STFT(t, f) = \int_{-\infty}^{\infty} x_j(t) \psi(t - \tau) e^{-2\pi i f \tau} d\tau. \quad (3)$$

With the time discretization, the formulation is rewritten as follows:

$$STFT_{n,f} = \sum_{k=n}^{n+N-1} x_{k,j} \psi_{k-n} e^{-2\pi i f k}, \quad (4)$$

where  $x_j(t)$  is a signal from sensor  $j$  to be transformed,  $\psi$  is the window function,  $N$  denotes the length of the segment. The 2D representation of STFT amplitude is called the spectrogram of the signal [15].

### C. Discrete Wavelet Transformation

The above STFT technique employed a fixed-width window to extract all frequency contents in time-series, but such a constant window could lead to missing information at lower or higher frequencies. Dealing with low-range frequency requires a long window, whereas, for high-range frequency, a shorter window is needed. To circumvent this drawback, the Wavelet Transform (WT) technique is proposed, using varying-length windows to capture better frequency information at different resolutions. Considering a time series  $x_j(t)$ , the continuous wavelet transform  $CWT_j$  is defined by the following convolution operator [16]:

$$CWT(a, b) = \int_{-\infty}^{\infty} \frac{1}{\sqrt{a}} \psi\left(\frac{t-b}{a}\right) x_j(t) dt, \quad (5)$$

where  $\psi$  is called mother wavelet, having wave form with finite duration and zero-average,  $a$  is a scale variable, and  $b$  is a translation variable. Owing to the scaling effect of  $a$ , the wavelet function  $\psi$  has a smaller time duration at high frequency, and longer duration at low frequency, conversely, resulting in the multi-scale resolution characteristic of WT.

For discrete time-series, discrete wavelet transform (DWT) is used in which the variables  $a$  and  $b$  are expressed as follows:

$$a = 2^i, \quad b = k \times 2^i \text{ with } i, k \in \mathbb{Z}, \quad (6)$$

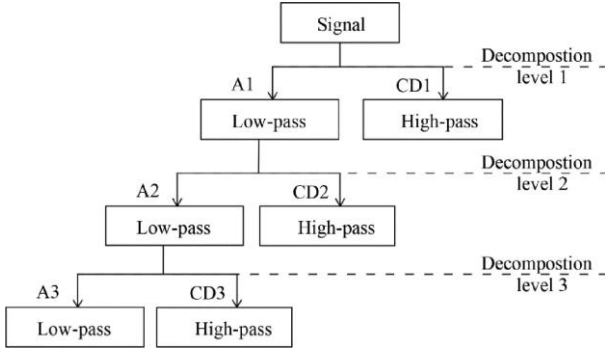


Fig. 1. Schematic representation of Discrete Wavelet tranformation.

and the DWT coefficient is written as [5]:

$$DWT_i = \sum_k a_{i,k} \psi_{i,k}(t), \quad (7)$$

where  $\psi_{i,k}(t)$  is discretized wavelets defined by

$$\psi_{i,k}(t) = 2^{-i/2} \psi(2^{-i}t - k), \quad (8)$$

and

$$a_{i,k} = \sum_{-\infty}^{\infty} x_j(t) \psi_{i,k}(t). \quad (9)$$

In terms of algorithm, the DWT can be implemented through the multi-rate filterbank algorithm as schematically shown in Fig. 1. There are multiple decomposition levels, each of which contains a half-band low-pass and high-pass filter, namely  $h(n)$  and  $g(n)$ . The signal is fed into the high-pass filter for the analysis of the high-frequency component, and low-pass filter for low-frequency ones. The above decomposition procedure can be repeated multiple times until a small number of samples is left. The original time series can be recovered by using the inverse DWT process and specified high-pass and low-pass filters.

#### D. Empirical Mode Decomposition

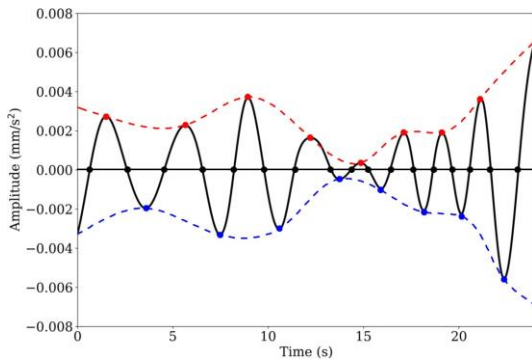


Fig. 2. Example of an intrinsic mode function with its zero-mean in solid line, maxima, and minima envelopes in dashed lines.

Although the WT can address the locality of signal processing, prevailing patterns of signals could evolve over time, hence the use of a fixed wavelet mother could miss certain underlying features. To address the non-linearity and nonstationarity of signals, Huang et al. [17], introduced an adaptive

method called Empirical Mode Decomposition, which can provide insight into time evolution of data property. To do this, the EMD decomposes the original signals into a finite number of functions called intrinsic mode functions (IMFs). An IMF must meet two required conditions: (1) the number of extrema, i.e. minima and maxima, must be equal or differ at most by one that of zero-crossings and (2) the mean value of the upper envelope of IMF formed by connecting local maxima and the lower envelope defined by the local minima is zero at any point.

Technically, the EMD method is realized by repeating the sifting process involving five following steps. First, the minima and maxima of the signal are identified. Second, two envelopes of the signal are created by using a cubic or higher-order interpolation connecting these minima and maxima. Third, the mean spline of these two envelopes is deduced. Next, the extrapolation is applied to relieve the swing effect at the ends of the signal where extrema values may not be available. Finally, the original signal is subtracted by the mean spline obtained from the third step. If the remaining wave satisfies two aforesaid conditions, then an IMF is obtained, otherwise steps 1-5 are repeated. The sifting process can be performed multiple times to obtain different IMF components until one of stopping criteria is met, for example, a predefined number of IMFs or the remaining signal is smaller than a given tolerance or becomes monotonic, i.e., no extrema can be identified. At the end of the decomposition procedure, one obtains a set of IMFs and a residue. The original signal can be reconstructed by adding all the IMFs and the residue.

$$x_j(t) = \sum_{m=1}^M IMF_m(t) + Res(t), \quad (10)$$

where  $IMF_m(t)$  is the  $m^{th}$  intrinsic mode function and  $Res(t)$  denotes the residue.

Raw acceleration data from a sensor are fed into the signal processing component with three algorithms presented above to extract relevant features. For AR, the feature used is the residual error computed as the deviation between original time-series with AR prediction. For DWT, extracted features are DWT coefficients in frequency domain as defined in Eq. (7). And for EMD, the used features are extracted IMFs expressed in time-histories as defined in Eq. (10). In order to bypass the scale difference between features, the standard scaler is applied, resulting in scaled features with zero mean unit variance, which serves as input for the hybrid 1DCNN-LSTM model. By doing so, one can profit the measurements from all sensors mounted across the structure, favoring the structural damage detection tasks which hardly accomplished by only using a single sensor such as damage localization or damage severity.

### III. DEEP LEARNING MODEL FOR STRUCTURAL HEALTH MONITORING

The proposed approach is schematically illustrated in Fig. 3, consisting of two main blocks: the preprocessing block whose details are described above, and the hybrid deep neural network which takes as input features processed from the previous block to perform structural health monitoring tasks.

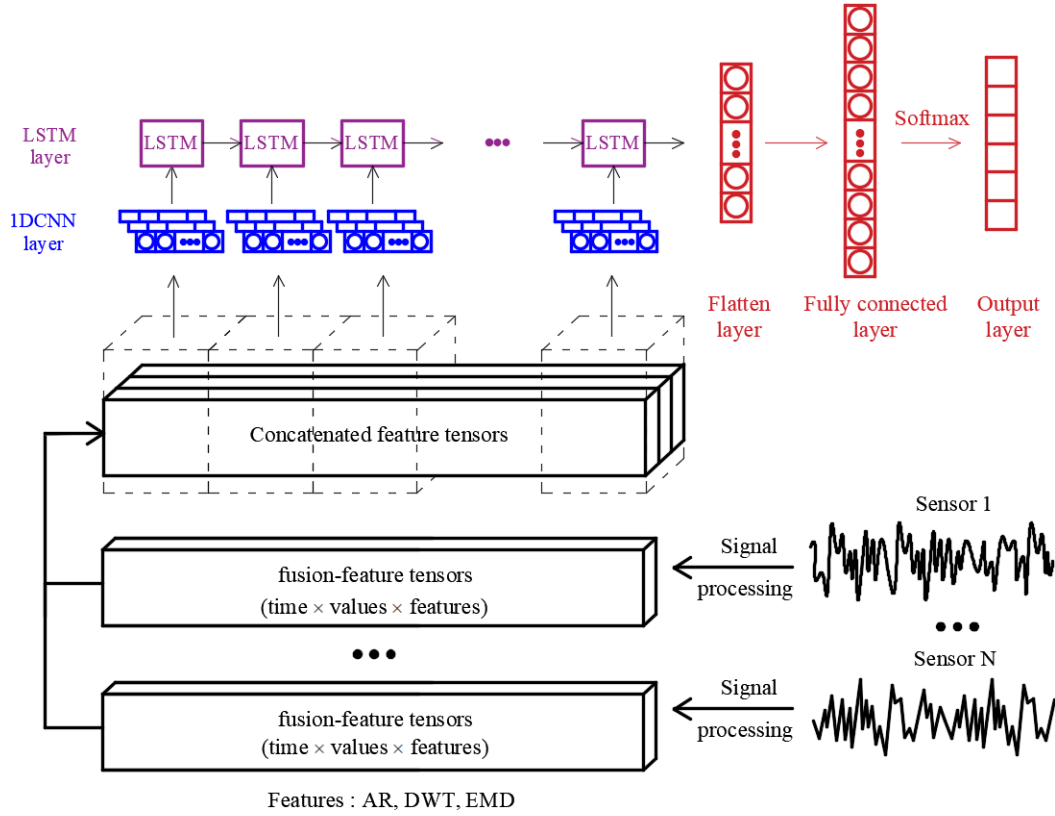


Fig. 3. Architecture of the hybrid 1DCNN-LSTM network.

#### A. Hybrid Deep Learning Model 1DCNN-LSTM

It is commonly acknowledged that the convolution neural networks (CNNs) can provide outstanding performance on signal classification and pattern recognition because of two reasons. First, its architecture is especially suitable for discovering local relationships among data points, second, it reduces the number of network parameters, thus leading to a lower computational complexity compared to conventional plain neural network architectures. The formula of one typical convolutional layer is expressed as follows [18]:

$$X^{conv} = conv1D(W^{conv}, X) \quad (11)$$

where  $X^{conv}$ ,  $W^{conv}$ , are respectively the output vector, weight matrix of the convolution layer,  $X$  is sensors input, and  $conv1D$  is the 1D convolution operator. The essential hyperparameters of the convolution layer is the number of kernel  $N_k$  signifying the number of local features extracted and the length of kernel  $L_k$  denoting the number of surrounding data points are aggregated.

Next,  $X^{conv}$  is fed into a LSTM layer, which uses information at multiple previous time steps to perceive insight into recent time steps, referred to as “long-term dependencies” as shown in Fig. 3. The fundamental theory of the LSTM can be found in the work of Hochreiter and Schmidhuber [19].

Introducing  $\mathbf{L}$  typical linear transformation of a combination of  $X_t^{conv}$  with  $N_k$  features at time step  $t$  and an output of hidden layer  $h_{t-1}$  with  $N_h$  features at previous step as

follows:

$$\mathbf{L}(h_{t-1}, X_t^{conv}) = W[h_{t-1}, X_t^{conv}] + b, \quad (12)$$

where  $W$  and  $b$  denote weight matrix and bias vector, it is noted that the number of features of  $\mathbf{L}$  is equal to that of hidden output  $h$ . Each cell of LSTM consists of three gates, namely forget gate  $f_f$ , input gate  $f_i$ , and output gate  $f_o$ , which involve applying the non-linear sigmoid function  $\sigma$  to a linear transformation  $\mathbf{L}$  as below:

$$\begin{aligned} f_f &= \sigma(\mathbf{L}_f(h_{t-1}, X_t^{conv})) \\ f_i &= \sigma(\mathbf{L}_i(h_{t-1}, X_t^{conv})) \\ f_o &= \sigma(\mathbf{L}_o(h_{t-1}, X_t^{conv})). \end{aligned} \quad (13)$$

On the other hand, a new candidate of information created at time step  $t$  is calculated by applying the  $\tanh$  activation function to a linear transformation of the concatenation  $[h_{t-1}; X_t^{conv}]$ :

$$C_t = \tanh(\mathbf{L}_c(h_{t-1}, X_t^{conv})), \quad (14)$$

Then, the candidate enters LSTM cells:

$$S_t = (f_f \odot h_{t-1}) \oplus (f_i \odot C_t), \quad (15)$$

and a hidden output of the LSTM cell at time step  $t$  is calculated at the output gate as follows:

$$h_t = f_o \odot S_t. \quad (16)$$

In these equations,  $\odot$  and  $\oplus$  stand for component-wise multiplication and addition of two vectors, respectively.

Having established the convolutional layer and LSTM's memory cell, the hybrid deep learning architecture is schematically illustrated in Fig. 3. Once vibration data enters into the network, it is divided into fixed-length segments, then the 1DCNN layer will extract local relationships between data points and their surrounding points before feeding to the memory cell of LSTM where long-term dependencies are identified and retained over time. The output of the last LSTM cell will be flattened and fed into a fully connected layer before being passed to the output layer with the softmax activation function to provide damage identification results. In this hybrid DL architecture, the essential hyperparameters which need to be determined further are the number of kernels  $N_k$ , the kernel length  $L_k$  in the convolution layer, and size of hidden output  $N_h$  at each LSTM cell. The present hybrid deep learning algorithm is implemented with the help of the open-source machine learning library Pytorch [20].

### B. 2D convolution neural network

The deep 2D convolution neural network utilizes as input data 2D representation of time series. The vibration signal is translated into the time-frequency representation through STFT, as presented in Section 2. Then a powerful image classifier in the Artificial Intelligent literature is applied to detect damaged structural cases. Here one adopted the ResNet-18 classifier [21] owing to its competitive performance, and explicit feed-forward architecture and used the transfer learning technique to fine-tune the model for structural damage identification tasks. The transfer learning technique allows exploiting general knowledge pretrained with a vast amount of data of different categories in a particular domain. For further details of the transfer learning technique, refer to [22]. Herein, the parameters of the ResNet-18 model are pretrained with millions of images from the ImageNet dataset from Google.

The workflow of the algorithm is illustrated in Fig. 4. Firstly, original vibration signal is fed into a spectrogram preprocess module to be converted into images of time-frequency representation, then entering the ResNet-18 models. Next, data continuously go through two fully connected layers before giving the classification results at the output layer using softmax activation function. The 2DCNN is implemented with the help of the deep learning library Fastai [23].

## IV. CASE STUDIES

### A. Case Study 1: Laboratory Data

In this section, the hybrid deep learning structure is applied to a study case involving experimentally measured vibration data from a three-story frame structure realized at Los Alamos National Laboratory [24] as shown in Fig. 5. The dataset is selected because of its validity, clarity and an appropriate number of available data. The frame consists of columns with 17.7 cm length and 2.5 x 0.6 cm<sup>2</sup> cross-section, and plates with 2.5 cm thickness and 30.5x30.5 cm<sup>2</sup> area. These structural components are made from aluminum and joined together using bolts. An electrodynamic shaker at the base floor serves to excite the structure randomly, the excitation is band-limited in the range of 20-150 Hz. At the top floor and

the third floor, an additional column (15.0 x 2.5 x 2.5 cm) and a bumper are installed, respectively. The contact between these two elements when the frame vibrates will induce non-linearity into the dynamic behavior of the frame. Each floor of the structure is equipped with an accelerometer of 1000 mV/g nominal sensitivity to measure the structure vibration. An acceleration signal is recorded for 25.6 s with a sampling frequency of 320 Hz. As the maximum excitation frequency is 150 Hz, then such sampling frequency is large enough to capture essential information content in the structure response.

The above default configuration of the structure is considered as the baseline condition. Afterward, a number of modifications are introduced to the structure to generate different structural state conditions. The modifications involve reducing 12.5% stiffness of one or two columns at each story, adding 19% extra floor's mass at the base or the 1st floor, and inducing contact between the suspended column at the top floor with the bumper. The structural states not involving contact are numbered from 1 to 9, and classified as undamaged states. Otherwise, structural states involving the intermittent contact between the column and the bumper are numbered from 10 to 17 and treated as damaged conditions. It is noteworthy that by varying frequency of contact between these two elements through their initial distance, one could generate different levels of damage in the structure (minor, medium, or major). Table 1 lists all 17 structural states with detailed descriptions. Following the working flow in Fig. 3, measured accelerations from four floors of the frame are processed, then fused into a global 3D tensor before entering the hybrid network. Note that here and throughout, a structural state is considered as an output class of the classification problem.

Applying the foregoing processing data techniques to the laboratory data, one can distill raw arbitrary acceleration signal into a set of canonical features which can benefit the damage detection of the structure. Figs 6 to 8 show representative results extracted from an acceleration signal at the top floor using the AR model, DWT, EMD, and STFT, respectively. To be specific, the parameters for each technique as follows: the order of AR model is set to 30 [24], the "haar" wavelet family is used for DWT [5], the sifting process for EMD can be found in [24] and for STFT, the length of windowed segment is set to 1000 which ensures to capture available details of vibration signal sampled at the frequency  $f_s = 322.58$  Hz.

After applying the AR technique, one obtained a vector of residual error in the time domain with a length of 8192, which was reshaped to a 3D tensor with a shape of (1,1,8192) for the feature fusion later, where 8192 was the original length of the acceleration signal. With DWT, one obtained a vector of DWT coefficients in the frequency domain, as shown in the bottom of Fig. 6, which was interpolated and reshaped into the same shape of (1,1,8192) for facilitating the fusion with time domain features in the numerical sense. Using EMD resulted in 10 IMFs (Fig. 7), which were combined in a 3D tensor with a shape of (1, 10, 8192). By fusing features extracted from AR, DWT, and EMD one received a 3D tensor of (1, 12, 8192) for one sensor, after that features from 4 sensors are concatenated, resulted in a global 3D tensors of (4, 12,



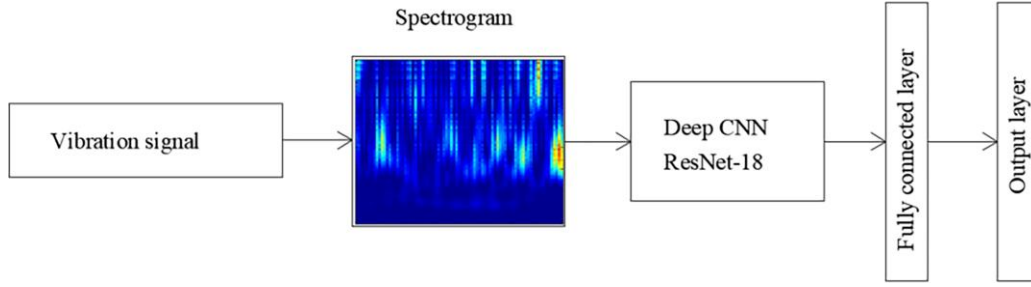


Fig. 4. Workflow of the 2DCNN-based method for structural damage detection.

TABLE I  
STRUCTURAL STATE CONDITIONS OF THE THREE-STORY FRAME STRUCTURE

State	1	2	3	4	5	6
Condition	0	0	0	0	0	0
Description	Baseline	Added mass	Added mass	Columnn stiffness reduction	Columnn stiffness reduction	Columnn stiffness reduction
State	7	8	9	10	11	12
Condition	0	0	0	1 (minor)	1 (medium)	1 (medium)
Description	Columnn stiffness reduction	Columnn stiffness reduction	Columnn stiffness reduction	0.2mm gap	0.15mm gap	0.13mm gap
State	13	14	15	16	17	
Condition	1 (medium)	1 (major)	1 (minor)	1 (minor)	1 (minor)	
Description	0.10mm gap	0.05mm gap	0.2mm gap, added mass	0.2mm gap, added mass	0.1mm gap, added mass	



Fig. 5. Three-story frame structure experiment [24].

8192) before feeding to the hybrid network.

1) *Data Augmentation*: In this subsection, the process of generating data for the hybrid deep learning is presented. In general, a large and well-balanced database favors the performance of Deep Learning algorithms, therefore data augmentation techniques are adopted to increase the size of the experimental data. In principle, the data augmentation technique introduces some minor changes in the original data without altering its underlying pattern. Herein the utilized techniques are flipping (rotation), scaling, permuting [25]. Flipping inverts the sign of the signal, scaling increases/decreases the magnitude of the raw data slightly by a random ratio from 5

to 10%, and permuting will swap two randomly selected small fractions (2% length) of the signal. Fig. 9 illustrates how data augmentation techniques work. After applying data augmentation techniques, the size of the final database increases up to 1000 time series, which is sufficient for training and validation of the proposed hybrid deep learning model.

2) *Data Preparation*: Formally, the database is split into three subsets, i.e., training, validation, and test one with a user-defined ratio. However, a single split might not ensure a well-balanced distribution of different structural conditions among sub-dataset. Therefore, the K-fold cross-validation strategy is employed to reduce the bias of the model. Firstly, the whole database is divided into training (90%) and test data (10%). Secondly, the training data is augmented with the presented data augmentation technique, before being split into the  $K$  equal portions. Here a common value  $K = 10$  is selected [26], meaning the training process will be iterated ten times, each time one different portion is used for validation, whereas the remaining serves for training as illustrated in Fig. 10. Once the model is trained, its final performance is reported on the test data unseen during training. To be specific, the size of test data and augmented training data are 60 and 540 samples, which results in global feature tensors with the shape of (60, 4, 12, 8192) and (540, 4, 12, 8192), respectively.

3) *Training Process*: As previously mentioned in Section 3, the hyperparameters of the proposed hybrid architecture are the number of kernels  $N_k$ , the kernel length  $L_k$ , in the

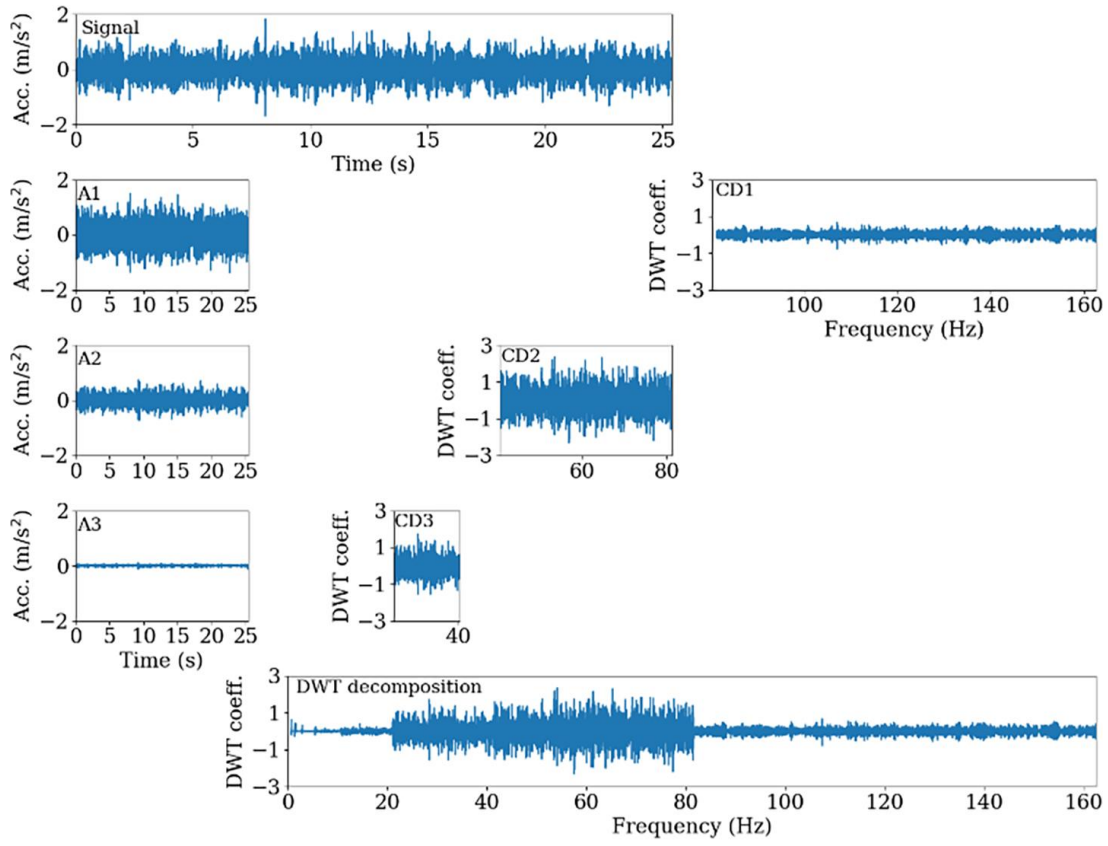


Fig. 6. DWT of a vibration signal. The first row is the original signal, the second to fourth rows are three levels of DWT decomposition where leftmost figures are remaining components after each DWT decomposition level, and rightmost figures are resulting DWT coefficients. The last row is the total DWT transform of the original signal.

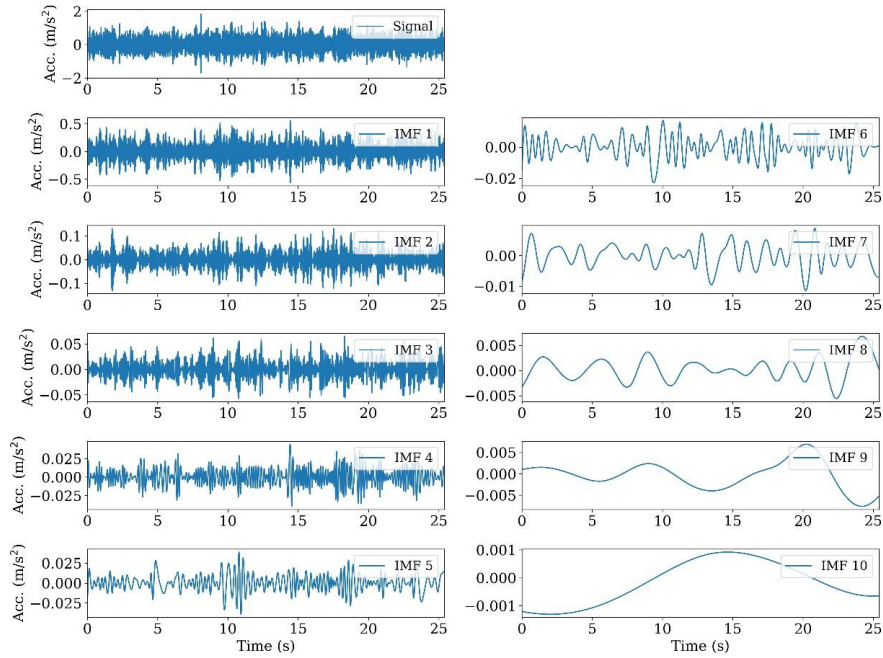


Fig. 7. EMD of a vibration signal. The first row is the original signal, the next rows are resulting IMFs. There are in total 10 IMFs for this example.



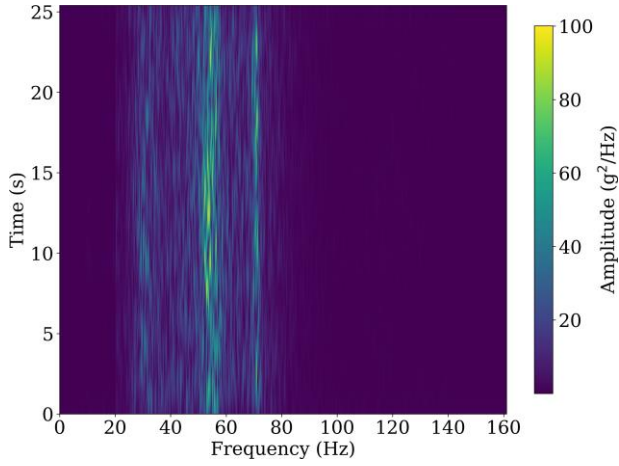


Fig. 8. Spectrogram of a vibration signal obtained by using the STFT. The brighter the color, the higher the amplitude, meaning that more signal energy concentrates over corresponding frequency ranges.

convolution layer, and the number of hidden layers  $N_h$  in LSTM cell. Actually, there is not existing a common way for the selection of the best parameters, but it depends on specific problems. Thus, one adopts the Grid search technique to test all possible combinations of hyperparameters for the identification of the optimal architecture. Specifically,  $k$  varies in the range  $[5, 50]$ ,  $L_k$  in  $[10, 100]$ , and  $N_h$  in  $[3, 30]$ . It is noted that other parameters are set by common values found in literature and fixed throughout the whole training process. Specifically, the optimizer is Adam [27], the learning rate standing for the relative amount of DL model weights updated after each optimization iteration, is set to  $lr = 0.0001$ , the number of epochs  $N_{epoch} = 200$ , the batch size, i.e., the number of data utilized in one optimization iteration is 32, and stop training early with a patience value of 20, meaning the training process will be stopped if no improvement is observed after 20 consecutive iterations. These values are defined to ensure covering as many details as possible in behaviors of DL model during the training process. It is recorded that the final hybrid deep learning model with the number of convolutional kernels  $N_{conv} = 50$ , the kernel length  $L_k = 200$ , and the number of LSTM cell's hidden layers  $N_h = 20$  provides the highest averaged accuracy of 93.5% and a standard deviation of 1.4% on the validation dataset.

TABLE II  
COMPARISON RESULTS OF DAMAGE DETECTION PERFORMANCE BETWEEN MODELS

Model	Raw	DWT	AR	EMD	Fusion	2DCNN
K-fold mean (%)	81.4	90.2	93.2	88.1	93.5	93.7
K-fold std (%)	6.6	2.5	1.2	1.5	1.4	1.2
CPU time (min)	26	28	26.5	41	45	118
Storage (Mb)	49	49	49	49	49	292

4) *Damage Detection Results:* Table II compares detection results obtained by each method, in which the first row presents the mean value of validation accuracy of 10-fold technique, the second row is the standard deviation, the last two rows are the used resources, i.e., CPU time and memory.

TABLE III  
COMPARISON RESULTS OF DAMAGE DETECTION PERFORMANCE BETWEEN MODELS PERFORMED ON NOISY DATABASE

Model	Raw	DWT	AR	EMD	Fusion	2DCNN
K-fold mean (%)	80.1	86.1	68	86	92.1	91.2
K-fold std (%)	5.9	2.1	3.8	1.7	1.8	1.5

Note that the calculated result with raw data is presented here for the comparison purpose, obtained by entering the raw data from sensors directly to the concatenate layer then the hybrid 1DCNN-LSTM, bypassing the preprocessing blocks (Fig. 3). As observed, the 2DCNN provides a high accuracy result of 93.7% on the validation data set, which is approximately achieved by the proposed feature-fusion method. The hybrid DL model using raw time-series data yield significantly lower accurate results, i.e., 81.4%, whereas models with DWT and EMD provide better results, i.e., 88.1% and 90.2% respectively. However, the method using only the popular AR technique can also nearly attain the same accuracy as the sophisticated 2DCNN and the feature-fusion technique. This confirms the usefulness of the popular AR technique, although simple but efficient in some scenarios. On the other hand, the required CPU time for the training process associated with each method clearly shows the high demanding resources from 2DCNN, both in time and storage.

In practice, measured vibrational data encompass inevitable noise related to data acquisition units, device instability, and so on. Therefore, it is of great importance to quantify the robustness of a SHM application in dealing with noisy data before applying to the real-world structure. It is noted that the data considered above are acquired in controlled laboratory conditions though some small amount of noise is also present, in the next step, the performance of methods when dealing with a more pronounced noise is explored. The white-noise is defined by the following equation:

$$X_{noise}(t) = X(t) + a \times \eta(t), \quad (17)$$

in which  $X(t)$  and  $X_{noise}(t)$  are original and added-noise time series, respectively,  $\eta(t)$  is a white noise time series with zero mean and unit variance,  $a$  is the noise amplitude compared to the RMS value of the signal amplitude  $X_{RMS} = (X^2_1 + \dots + X^2_n)^{1/2}$ , where  $X_i$  is a value of the signal at time instant  $t_i$ . The white noise reflects the avoidable unknown ambient excitation, whose amplitude  $a$  can be set to 10% on average as considered in [28], [29]. Table III and Fig. 11 present in detail performance results for methods of interest on noisy data. It is noticed that the performance of the hybrid-DL using only AR coefficients decreases drastically with added noise, from about 90% down to below 70%, while the 2DCNN and fusion-feature method can retain sufficiently high accurate results of 91%. The observed decrease in performance of methods using DWT and EMD is also significantly lower than that of AR, i.e., a reduction of 4.0% and 2.1%, respectively. This can be explained by the fact that the incorporated white noise has flat broadband frequency spectra in nature, hence the feature extraction method in the frequency domain and time-frequency domain such as DWT, EMD, and STFT still discern

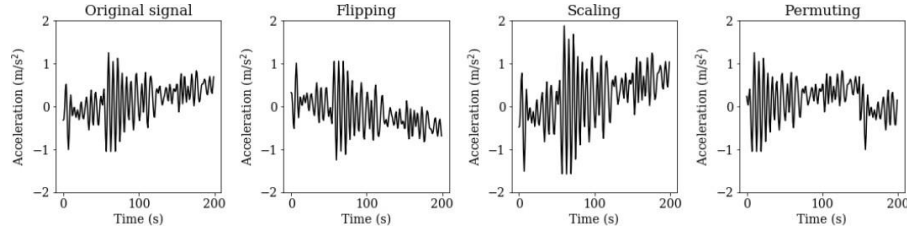


Fig. 9. Data augmentation techniques for time-series data.

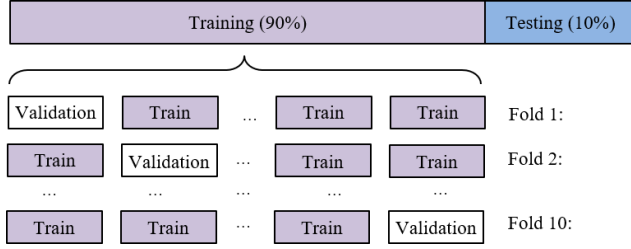


Fig. 10. 10-fold cross-validation strategy.

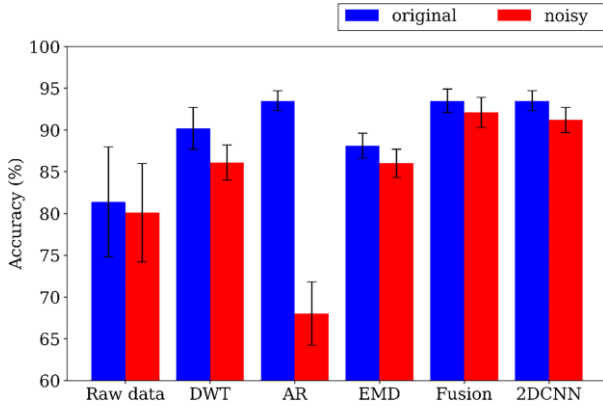


Fig. 11. Comparison of structural damage detection obtained by different models. The fusion method and 2DCNN provide the best results.

the underlying frequency components from the noise. Indeed, there are methods using AR coefficients, which are able to address noisy data effectively, for example, the works in [30], [19] extracting modal characteristics of the structure from AR coefficients. However, these methods require further mathematical transformation and expert knowledge in the dynamics of structures. Besides, to ease the fusion with other signal processing techniques, residues obtained from AR models in a time-series form is preferable than tabular data of frequency values or mode shape vectors, in this work.

In short, these above results imply that fusing advantages of different feature extraction techniques favor the hybrid DL method's robustness and reliability when encountering different scenarios in reality.

5) *Damage Severity Results*: As shown in Table I, the damaged state of the structure can be divided further in order as minor, medium, and major damage. Then, the proposed method is adapted to address the damage severity task by fine-tuning the numbers of perceptron at the output layer to four

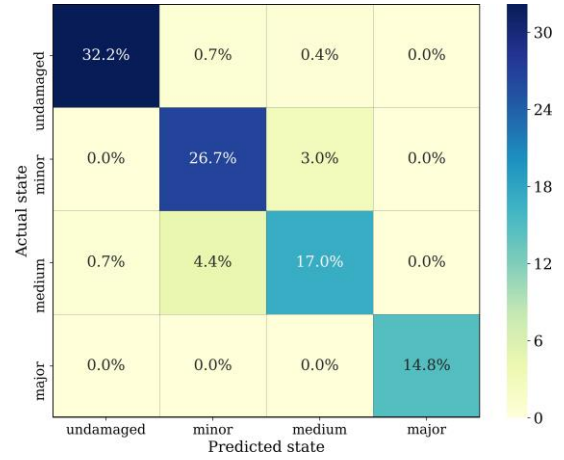


Fig. 12. Confusion matrix for damage severity classification. Resulting global classification accuracy is 90.7% by summing diagonal terms.

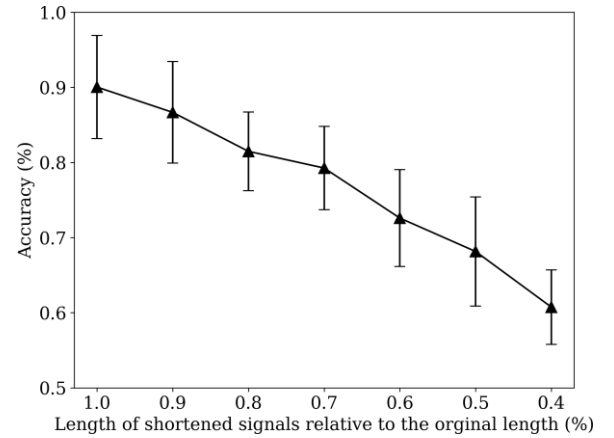


Fig. 13. Damage severity performance versus the length of shortened signals.

and relabelling the database by corresponding damage levels. Note that it is not a trivial task as the difference between the minor damage state with the pristine one, or between two consecutive damage levels, is subtle and can be overlapped by random noise, that is why the required classifier should possess robust discriminative power.

After carrying the training stage with 10-fold cross-validation, the network is tested on the unseen and also noisy data. Note that The network architecture presented previously is kept unchanged, i.e.,  $N_{conv}=50$ ,  $L_k=200$ ,  $N_h = 20$ . Fig. 12 illustrates the detection results via a confusion matrix where

TABLE IV  
LABELING FOR DAMAGE LOCALIZATION TASK OF THE THREE-STORY FRAME STRUCTURE

State	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18
Location	S0	S0	S0	S1	S1	S2	S2	S3	S3	S4	S4	S4	S4	S4	S4	S4	S4	S4

S0: No damage. S1, S2, S3: stiffness reduction of columns at the first, second, and third story, respectively. S4: intermittent contact at the fourth story.

the diagonal terms denote the correctly detected damage cases in terms of global percentages, the off-diagonal terms for false detection, and all values of the matrix sum up to 100%. It is ideal that all non-diagonal values are zeros. Thus, by summing the diagonal terms, one obtains the global classification accuracy of the proposed method as high as 90.7%. These results reaffirm the capability in capturing the underlying dynamical features and mapping them to the corresponding structural states of the featured-fusion approach.

Next, one investigates the impact of the effective length of the signal on the detection performance. The same process with the damage severity task is carried out except for the length of the signal, which varies from 40% to 100% of the original one. For instance, a 50% shortened signal means only the first half of the signal is taken as input for the proposed approach, another half is removed. The evolution of the detection accuracy in a function of the relative length of the shortened signal is depicted in Fig. 13. As expected, there is a trade-off between the performance and the length as a clear downward trend is observed, for example, a 20% reduction in length leads to 10% decrease in accuracy (from 90% to around 80%).

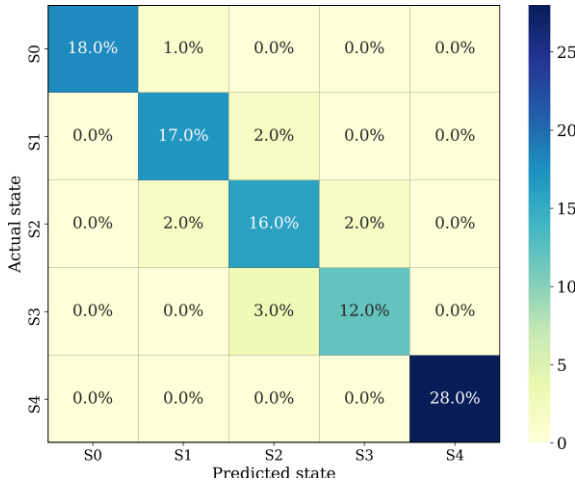


Fig. 14. Confusion matrix for damage localization classification. Resulting global classification accuracy is 91.0% by summing diagonal terms.

6) *Damage Localization Task*: As demonstrated, the feature-fusion hybrid DL method can perform the level 1 of SSD, i.e., damage detection with high accuracy, then in this paragraph the present method is adapted to perform the level 2 of SSD, i.e., damage localization. To this end, the experimental database is relabelled, each time-series is annotated by the story where modification is realized accordingly, as listed in Tables IV. Structural states 1 through 3 are labeled as S0,

meaning no damage is introduced, states 4, 5 as S1, states 6, 7 as S2 and states 8, 9 as S3, since the column stiffness at the first story, the second story, and the third story are reduced, respectively. States 10 through 17 are labeled as S4 because the intermittent contact caused by the additional short column happens at the fourth story. Next, a similar procedure involving data generation, data augmentation, training, and validation procedure, as described above, is conducted. Fig. 14 details the localization results for each class, where diagonal terms denote accurate predictions, and off-diagonal terms refer to misclassifications. Summing the diagonal terms yields a global classification accuracy of 91.0%. This result shows that the proposed method is applicable for level 2 of SDD, and the conversion between different SDD tasks is fairly straightforward without requiring any complex and tedious manual calculations.

### B. Case Study 2: My Thuan Stayed-Bridge

For the second case study, ones apply the proposed fusion feature DL approaches to a synthetic database of the full-scale bridge My Thuan in Vietnam, which is a stayed-cable bridge playing a vital role in the transport system. Among the most critical structural elements of the bridge, cables have a great impact on the dynamic behavior of the structure. A significant loss in the cable's prestressed force will result in reduced structure rigidity, then causing potential excessive vibration and inducing further damages such as crack, fatigue, and so on. Hence, using the present approach provides an alternative approach to quickly and remotely assess the location of tendons with tension loss based on the dynamic response of the bridge before requiring workers to perform in-situ tests to check tendons thoroughly.

1) *Finite Element Model*: Fig. 15 presents main geometric parameters of the bridge: the total length of the bridge is 650 m with a 350 central span and two side spans of 150 m, the bridge reinforced concrete deck has a width of 23.6 m, a depth of 0.2 m, and is supported by two longitudinal girders of 2.0 m depth and transverse beams placed at 5.2 m intervals. The two H-shaped bridge towers have a total height of 129.5 m, including legs of 2.5 m width. The materials of the superstructure components are concrete of Grade 50 with  $E_c=35.75$  GPa, a volumic density of  $2400 \text{ kg/m}^3$ , compressive strength of  $f_c^t=50$  MPa. The system of cables consists of 128 cables with a diameter of 15.2 mm, an elastic modulus of 195 GPa, and a tensile strength  $f_{pu} = 1860$  MPa, dividing into four groups, each connected to one pylon. As the layout of the cables is symmetric, the groups of cables have similar influences on the bridge's behavior. The cables are annotated from 1 through 32 within each group, which is also the number

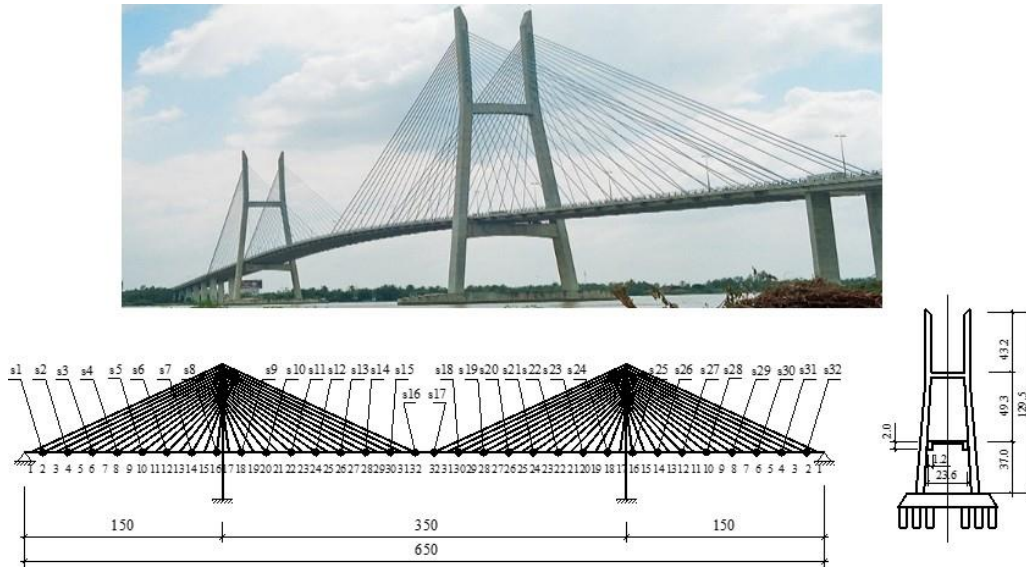


Fig. 15. My Thuan stayed-bridge in Vietnam.

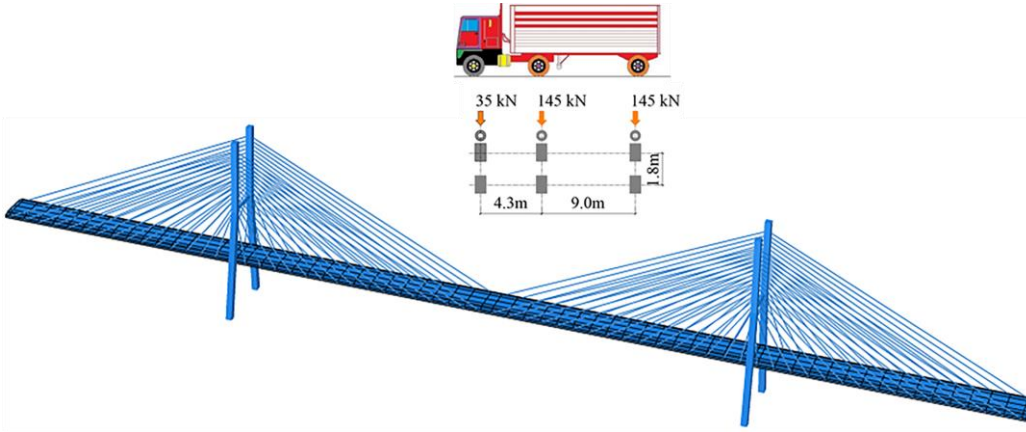


Fig. 16. Finite element model of the stayed-bridge.

TABLE V  
TENSION FORCE IN CABLES

Cable	1	2	3	4	5	6	7	8	9	10	11
Measured Force (kN)	6395	5264	4554	3668	3459	3459	3481	3478	3266	3128	2935
Length (m)	177.5	173.8	170.4	162.4	152.5	142.8	133.1	123.6	114.3	105.2	96.4
Cable	12	13	14	15	16	17	18	19	20	21	22
Measured Force (kN)	2543	2267	2497	2042	2171	2512	2376	1938	2135	2508	2743
Length (m)	88.0	80.0	72.6	65.5	58.5	57.4	63.4	69.6	76.4	83.9	91.9
Cable	23	24	25	26	27	28	29	30	31	32	
Measured Force (kN)	2403	3033	2947	3145	3417	3688	4077	4006	4489	5967	
Length (m)	100.4	109.2	118.3	127.6	137.1	146.8	156.5	165.4	176.3	186.4	

of output classes of the DL model for this case study. The prestressed force in each cable is provided in detail in Table V, according to as-built design drawings.

Herein, the structural damage detection task is referred to as the damage localization, meaning that the proposed method is used to inversely identify the location of the cable

with tension loss based on acceleration time series computed at the points uniformly distributed across the bridge. It is widely acknowledged that acceleration is rich in discriminative features, thus suitable to take as inputs to SDD models [31]. To be specific, there are 32 measured points on each side of the bridge, as illustrated in Fig. 15, resulting in a total of



64 points. The same workflow presented for the first example is carried out, including using AR model, DWT, and EMD to extract salient features in both time and frequency domain from raw acceleration time series and the k-fold validation strategy. However, here one needs to integrate information from a significantly larger number of sensors, which can be efficiently realized by using the convolution layer in the proposed hybrid DL model.

TABLE VI  
COMPARISON RESULTS OF DAMAGE LOCALIZATION PERFORMANCE  
BETWEEN MODELS

Model	Raw	DWT	AR	EMD	Fusion	2DCNN
Accuracy (%)	22.5	28.0	43.0	78.0	84.5	85.2
CPU time (min)	110	135	125	170	180	486
Storage (Gb)	1.3	1.3	1.3	1.3	1.3	2.9

To generate the database for the DL model, one adopts the Monte Carlo simulation upon a calibrated Finite Element Model (FEM) of the bridge using model updating technique and in-situ measured data. At first, an initial 3D FEM of the bridge is constructed from the as-built design drawings using the software Abaqus [32], then a series of measurements is carried out to measure the vibration of each cable in service, i.e., under vehicular loads. After that, an optimization-based model updating technique is used to minimize the difference between modal characteristics of cables with the numerical counterpart, including eigenfrequencies and mode shapes. As detailed solutions for similar problems can be found in the optimization literature [33], [34], thus for brevity, one only presents measured forces in cables in Table V.

In terms of the FEM, the Abaqus software is adopted because of its modeling power and practical Python interface programming to build the bridge model. The bridge deck is modeled by four noded S4R shell elements, the pylons and reinforced concrete girders are modeled using 3D beam elements, the stay cables are modeled using two-noded T3D2 truss elements subjected to pre-stressed action. The pre-stressed value per strand is obtained by dividing the tension force by the strand area and is modeled as an initial condition, directly applied to cable elements at the beginning of the analysis using predefined mechanical fields. In this work the source of excitation is the vehicular load which is the most common type of load encountered in the bridge structure. The vehicular load is modeled using a standard HS20 truck after the American Association of State Highway and Transportation Officials specifications [35] moving with a constant velocity whose details are highlighted in Fig. 16. In order to enrich the database for training the DL model, the number of cars varies from 1 to 5, the velocity of the cars is in the range of [10, 15, 20, 25, 30] m/s, and various damage scenarios are introduced, involving 100% tension loss at a random cable, resulting in an extensive series of 10000 simulations. Afterward, the vertical accelerations at 64 virtual sensors uniformly spaced along the bridge deck are virtually recorded, and fed into the present approach to identify the respective location of the defected cable. After the data preparation step, the test data and training data have the shape

of (1000, 64, 12, 6000) and (9000, 64, 12, 6000), respectively where 64 is the number of sensors, 12 is the number of extracted features, i.e., AR, DWT, IMF, and 6000 is the length of time-series measured for 60 s with a sampling frequency of 100 Hz.

2) *Computation results:* Table VI compares the obtained detection accuracy using the feature fusion approach with the powerful 2DCNN, as well as models using separately extracted features. Apparently, the DL-based method can properly perform the damage localization tasks based on acceleration signals. Such a task is not trivial as it requires a powerful discrimination ability because the number of outputs herein is 16 times as much as that of the damage detection task with binary outputs (damaged /undamaged) in the first case study. Furthermore, the proposed approach can equivalently achieve a considerably high accurate result of about 85% as the 2DCNN, following by the model using EMD, AR, DWT, and raw data. Fig. 17 shows in more detail the accuracy percentage for each cable through a confusion matrix.

All the calculations were conducted on a high-end machine equipped with 16 cores CPU Intel Xeon, 64-GB RAM, and 2 Geforce GTX 1080Ti GPU. The model using directly raw data requires the least CPU time of 110 minutes; the DWT and AR have higher CPU time, mainly due to the feature extraction step, as listed in Table VI. For the EMD, as the number of features increases to 10, corresponding to a training data with the shape of (9000, 64, 10, 6000), the CPU time increases to 170 minutes, and for the model with feature fusion, i.e., the number of features is 12, the CPU is 180 minutes. As the calculations were realized with the library Pytorch, which allows the parallel computation and take advantage of GPUs; thus, the computational time with fusion-features can be reduced. On the other hand, the factors having considerable influences on the CPU time are the number of data and the length of time-series, that is why the CPU time in this example is significantly larger than those in the case study. In comparison, 2DCNN demands 490 minutes for the training process and more than twofold memory volume for respective 2D representation of each time-series.

In addition, the effect of the number of virtual sensors on the model performance is explored by varying the former in the range of [1, 2, 4, 8, 16, 32, 48, 64]. As can be seen in Fig. 18, a smaller number of sensors leads to significantly reduced detection accuracy. On the other aspect, for this example, the DWT and the raw time-series yield low accurate detection results despite increasing the number of sensors, possibly because the mass of vehicular load is fairly small compared to that of the bridge. Then, the difference between the frequency range of forced vibration responses with free vibration of the bridge is subtle, and limit the capacity of the frequency-domain method. Besides, the time-domain such as the AR model gives better accuracy, and the EMD provides dominant contributions to the performance of the fusion-feature method. Overall, a stable trend is observed when more than 32 sensors are used.

### C. Case Study 3: Progressive Damage Tests of Z24 Bridge

In this subsection, the proposed framework is extended to a real database of the Z24 Bridge in Switzerland from the

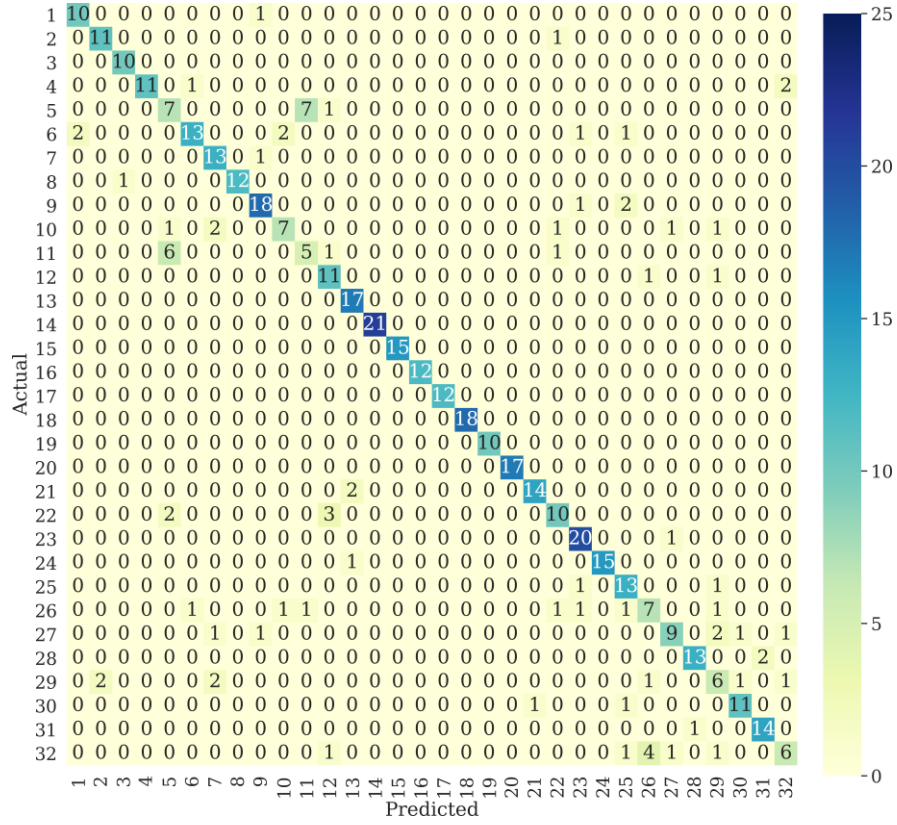


Fig. 17. Confusion matrix results of the damage localization task for the stayed-bridge structure.

TABLE VII  
LABELING FOR THE SDD TASK OF THE Z24 BRIDGE.

State	1	2	3	4	5	6	7	8
Description	No damage	No damage	20 mm settlement	40 mm settlement	80 mm settlement	95 mm settlement	Tilt of foundation	No damage
State	9	10	11	12	13	14	15	16
Description	12 m <sup>2</sup> spalling	24 m <sup>2</sup> spalling	1 m landslide	1 column failure	2 anchors failure	4 anchors failure	2 tendons failure	4 tendons failure

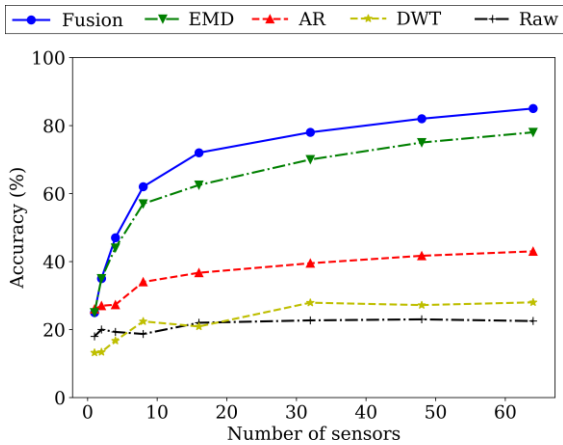


Fig. 18. Model accuracy in functions of the number of sensors.

BRITE-EURAM project SIMCES (System Identification to Monitor Civil Engineering Structures) [36]. The Z24 bridge is a prestressed bridge overpassing a highway connecting Bern and Zurich. The bridge consists of three spans with a total length of about 60 m, as illustrated in 19. Before the bridge was completely demolished, different progressive damage scenarios were carried out over a month in 2008, including lowering, lifting of piers, spalling of concrete, failure of anchor heads, rupture of prestressed tendons. Details of progressive damage tests (PDT) and corresponding labels are reported in Table VII. A system of sensors was strategically installed across the bridge to measure its structural responses during PDTs. For each PDT, nine test setups were conducted, and for each setup, 33 acceleration time-series from various sensors were collected, of which five time-series, namely R1-V, R2-T, R2-V, R2-L, and R3-V were common between setup tests, where R1, R2, R3 are the location of sensors, V, T, L denote the directions of displacement, i.e., vertical, transversal



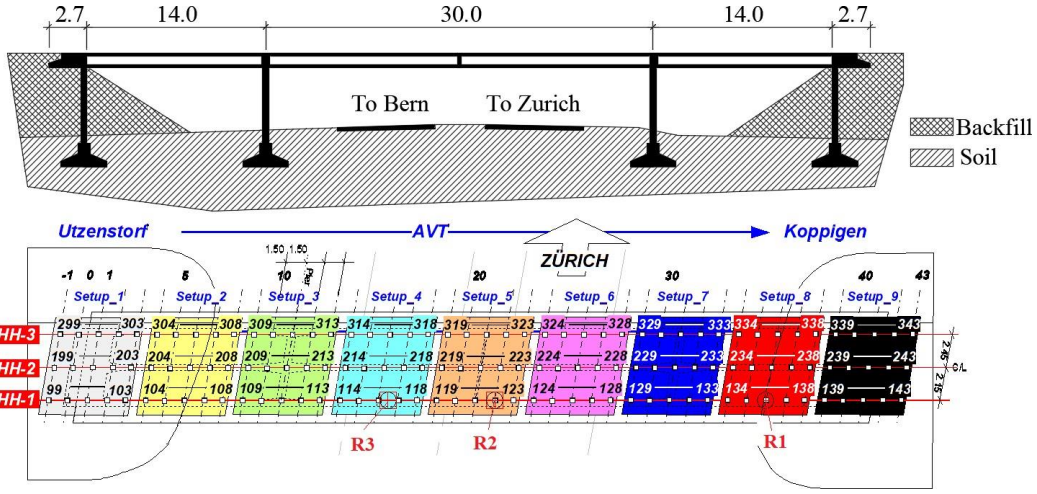


Fig. 19. Z24 bridge in Switzerland: The geometry of the bridge is depicted at the top, locations of sensors are presented at the bottom.

and longitudinal.

TABLE VIII  
SDD RESULTS FOR PROGRESSIVE DAMAGE TEST OF Z24 BRIDGE.

Model	Raw	DWT	AR	EMD	Fusion
Accuracy (%)	61	78.6	70.6	81.2	90.1

In order to prepare databases for the DL model, a similar procedure successfully reported in [4] is adopted. More specifically, data from a sensor is sampled with a frequency of 100 Hz, resulting in a signal of 65,568 samples, which is further divided into 8 time-series of length 8000. Hence, for each PDT with nine test setups, 72 time-series are extracted from one sensor. Then, the obtained database of Z24 consists of 1224 groups of five time-series, each group labeled from 1 to 16 according to PDT associated. Applying the data preparation step results in a test data and augmented training data with the shape of (231, 5, 12, 8000) and (4769, 5, 12, 8000), respectively where 5 is the number of sensors, 12 is the number of extracted features, i.e., AR, DWT, IMF, and 8000 is the length of time-series.

Next, the 10-fold cross-validation strategy is applied to train and valid the detection accuracy of the proposed approach. The key parameters of the DL architecture after fine-tuning for this study-case is as follows: the number of convolution kernels  $N_k = 200$ , the length of convolution kernel  $L_k = 100$  and the size of hidden output of LSTM cell  $N_h = 100$ . Table. VIII summarizes the damage detection results obtained by the fusion-feature method and their counterparts using one extracted feature. It can be seen that the fusion-feature method achieves a highly accurate SSD result of 90.1%, more detailed classification result for each PDT is illustrated via the confusion matrix in Fig. 20, moreover, PDTs in same categories are also clearly separated, for example, PDT 9 and PDT 10 for concrete spalling, PDT 15 and 16 for tension failure, which are sometimes misclassified by other methods [4].

To provide more intermediate results about the performance of the hybrid model, the t-Distributed Stochastic Neighbor

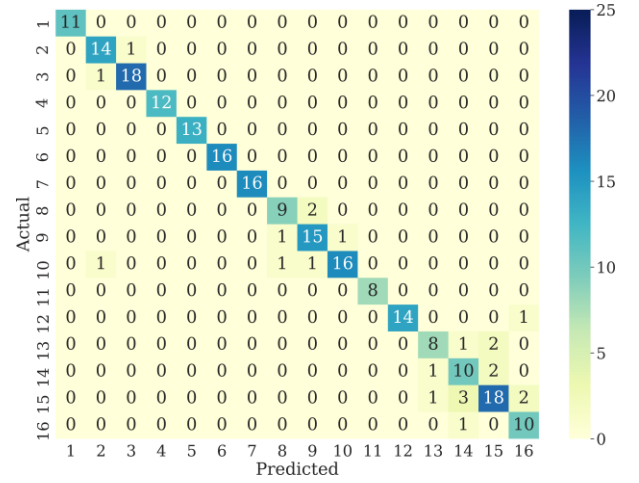


Fig. 20. Confusion matrix for SDD results of Z24 bridge.

Embedding (t-SNE) [37] method is employed to show the clustering of different conditions of the structure. It is expected that measurements from a given structural condition will be grouped into the same cluster, and well separated from others. In contrast, if data points are mixed together, meaning further improvement is required to achieve a better SDD performance. Fig. 21 illustrates the t-SNE representation on test data obtained at different main steps of the hybrid IDCNN-LSTM, namely, after the IDCNN step, the LSTM step, and the fully connected (FC) step. It can be seen that at the IDCNN step, data points from different classes overlap together, no observable clustering is obtained, while after the LSTM step, the clustering is much better, data points are divided into different groups, though some classes are not clearly separated. At the fully connected step, data points are almost split; only a small number of data points are mixed at their corresponding class boundaries; for example, those from classes 14 and 15.

In short, the validity of the present method is successfully proved through experimental data from a real-world bridge.

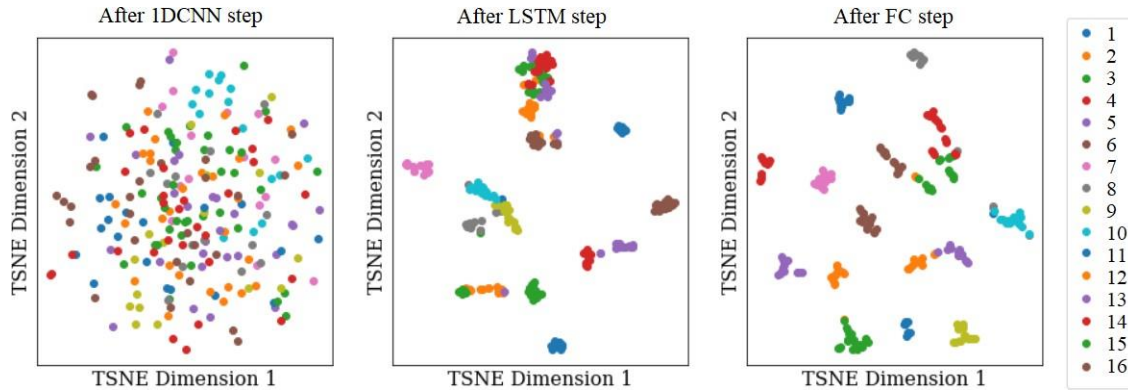


Fig. 21. t-SNE visualization of damage localization task obtained at main steps of the hybrid 1DCNN-LSTM algorithm

## V. CONCLUSION

In this work, a novelty method for Structural Damage Detection was developed based on the feature fusion technique and a hybrid deep learning architecture for improving the detection performance with low required resources in terms of computational cost and storage capacity. Remarkably, the present method works on pure data; thus, a numerical model of the structure is not required, which allows addressing real-world problems in which pure forced excitation is challenging to identify. Moreover, the method is able to perform not only level 1 of damage assessment but also level 2 (damage localization). Such a SDD method enables to monitor structures in a smart and real-time fashion.

The applicability and efficiency of the proposed method were first validated through a case study with experimental vibrational data obtained from a three-story frame. Two levels of SDD were conducted, i.e., damage detection and damage localization, with both original data and data contaminated by random noise. It was found that the feature fusion method outperforms the other ones using separately features in terms of accuracy and robustness. When comparing with the sophisticated 2DCNN method, the proposed one provided equivalent performance. Moreover, it significantly reduced both time and memory complexity, which would be costly when performing long term monitoring and when structures become more complex. Secondly, real data from progressive damage tests of the Z24 bridge were used to support the validity of the fusion-feature method. It showed that the proposed method consistently achieves highly accurate damage detection results, while performances of methods using separately extracted features could vary significantly depending on specific SDD tasks. Next, the method was applied to the full-scale cable-stayed bridge My Thuan in Vietnam for the detection of tension loss in prestressed cables. The case study emphasized the discrimination power of the proposed method in the detection of structural damage when dealing with a multi-classification problem of a complex structure using simultaneously multiple time-series input. Moreover, the low time complexity and memory usage of the proposed method facilitated parametric studies, which quantified the influence of the number of sensors on the detection accuracy, providing tradeoff con-

straints for engineers and owners when drawing an optimized maintenance strategy.

In future works, it is noteworthy to extend the method to an online framework where measured data are collected from IoT sensors, then uploading to cloud servers. After that, the present SDD method can analyze data and provide informative structural assessments for responsible personnel from anywhere in the world through a web application. Another exciting direction is to incorporate probabilistic analysis into Deep Learning frameworks, then even with limited input data, one is still able to perform SDD tasks with corresponding confidence intervals. When more data are available, the model will be updated, and the variability of the detection results will reduce, i.e., the confidence interval will become narrower.

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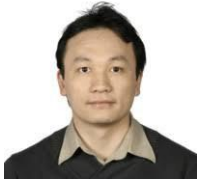
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